



ServoTube 38[®] INSTALLATION GUIDE

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WARRANTY

Copley Motion Systems guarantees its equipment against faulty components for a period of twelve months from delivery. Replacement components will be free of charge. Copley Motion Systems shall not in any event be liable for consequential damage or loss.

Copley Motion Systems operates a customer care facility and all requests for repair and replacement should be directed to the Customer Care Department. The serial number of the equipment should be quoted in any communications. The right to change specification and price is reserved by Copley Motion Systems.

DISCLAIMER

Copley Motion Systems makes no guarantees of any kind with regard to this manual. Copley Motion Systems shall not be liable for errors contained herein or for consequential or incidental damages incurred as a result of acting on information contained in the manual.

CUSTOMER CARE

For enquiries relating to the operation and use of the ServoTube 38 described in this Manual please contact the Customer Care Helpdesk, Telephone : +44 (0)1268 287070.

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Copley Motion Systems 2005

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ServoTube 38 INSTALLATION GUIDE

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WARNINGS

Warning symbols and meanings

In this User Manual warning symbols are used. These are intended to alert you to the potential hazards to personnel which are associated with the equipment described, in all aspects of use, including handling, installation, operation and maintenance.



Heart pacemakers. Personnel fitted with pacemakers must not handle or work on this equipment.



Strong magnets. The thrust rod contains powerful magnets and will strongly attract ferrous objects. Damage can occur to computer disks and credit cards.



Electric shock. Potentially lethal voltages may be present during the commissioning and servicing of this equipment. Isolate and disconnect all sources of electrical supply before working on the equipment. Particular care needs to be taken when working on or around motor phase connections.



Hot surface. Surface temperatures of up to 80 °C can be present during the commissioning and servicing of this equipment. Allow the forcer and thrust rod to cool before working on the equipment.



Heavy object. May need two people to lift.



Crush hazard. The forcer may move unexpectedly. Always isolate all sources of electrical supply before working on the equipment.



General hazard. Follow the advice given.

Electrical safety

This equipment must be earthed using the green/yellow conductor.

EMC precautions

This equipment is intended for use in a light industrial environment. It is recommended that the following precautions be observed during installation:

- Keep all cable lengths to a minimum.
- Provide as much physical separation as possible between power and signal cables. In particular, avoid long, parallel runs of cables.
- Maintain screen continuity throughout the cable run.
- Use 360 degree screen terminations where possible. “Pig-tail” terminations are not recommended.
- It is the responsibility of the User to ensure compliance with any local electrical and EMC regulations in force at the time of installation.

READER'S NOTES

GENERAL

This manual describes the Installation, Maintenance and Spares of the ServoTube 38 linear motor.

ASSOCIATED PUBLICATIONS

The following publications are associated with the ServoTube 38 User Manual.

Title	Reference Number
ServoTube Applications Guide	UM03012
XTA Data sheet	DS01093
XTB Data sheet	DS01094
Xenus User Guide	-
Xenus Data Sheet	-

Chapter 1

Product Overview

SERVOTUBE 38 ACTUATOR

The ServoTube 38 Actuator is an optimal solution for industrial position control. Faster than a ballscrew with the clean reliability of a linear motor, the ServoTube 38 is a cost-effective alternative to air cylinders in applications requiring greater flexibility and control.

Four models

The ServoTube 38 Actuator incorporates an IP67 rated forcer and a sealed stainless steel thrust rod enclosing rare-earth magnets. Four models deliver a continuous force range of 137-276 N (31-62 lb) with peak forces up to 1860N (418 lb). Nine stroke lengths are available from 33- 318 mm

The patented magnetic design of ServoTube 38 generates 25 micron (0.98 mil) repeatability and 400 micron (16 mil) accuracy from a non-contact, integral position sensor. No external encoder is required. Position output is industry standard 1V pk-pk sin/cos signals.

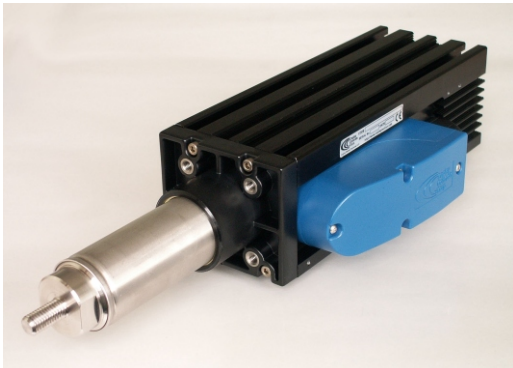


Figure 1.1 - ServoTube 38 Actuator

Maintenance free

The XTA has an internal dry bearing which provides a clean, quiet, maintenance free performance. Life expectancy far exceeds typical ballscrew solutions. The ServoTube 38 Actuator is ideal for push/pull/lift material handling, packaging and automated assembly applications. ServoTube 38 accepts a range of industry standard accessories for simple mechanical integration.

Plug and Play

Flexible mid-stroke position control is simple with Xenus - a matched, self-tuning indexer complete with plug-and-play cabling. Simply select your ServoTube 38

model number and the system comes up tuned and ready to run. Clear diagnostics make system commissioning easy. Fill in the blanks to define position, velocity and acceleration.

SERVOTUBE 38

ServoTube 38 delivers the speed of a belt-drive system with the clean reliability of a linear motor at a price unprecedented in the industry. Familiar form factor, integral position feedback and large air gap make installation simple.

The ServoTube 38 motor components comprise an IP67 rated forcer and a sealed stainless steel thrust rod enclosing rare-earth magnets. Four models deliver a continuous force range of 137-276 N (31-62 lb) with peak forces up to 1860 N (418 lb). A range of Thrust Rods are available for travel lengths up to 1362 mm.



Figure 1.2 - ServoTube 38

The patented magnetic design of ServoTube 38 generates 25 micron (0.98 mil) repeatability and 400 micron (16 mil) accuracy from a non-contact, integral position sensor. No external encoder is required. Position output is industry standard 1V pk-pk sin/cos signals.

Easy Integration

ServoTube 38 is an ideal OEM solution for easy integration into pick-and-place gantries and general purpose material handling machines. The load is mounted directly to the Forcer typically supported by a single bearing rail. The Thrust Rod is mounted at both ends, similar to a ballscrew. A large air gap reduces alignment constraints.

The tubular motor has superior thermal efficiency, radiating heat uniformly. High duty cycles are possible without the need for forced-air or water cooling.

Amplifiers

ServoTube 38 is complemented by a range of matched, self-tuning servo-amplifiers and indexers complete with plug-and-play cabling. Amplifiers interface easily to PLCs and feature CANopen network connectivity for distributed control applications.

Chapter 2

Installation



UNPACKING

- Check packaging for signs of damage.



- Metal surfaces may be hot or below 0°C following prolonged storage.

- Remove packaging. Do not discard. In the event of items requiring return, it is recommended that the original packaging be used.
- Ensure that the delivery note correctly reflects your order and the items delivered.
- Check equipment for signs of damage. Never use the equipment if it appears damaged in any way.
- Read the User Guide before installing and using this equipment.

INSTALLATION

Intended operating environment

This equipment is intended for use in an environment within the following conditions: -

Operating temperature	0 to +40 °C
Storage temperature	-25 to +70 °C
Humidity (relative)	0 to 95% non-condensing
Altitude (above mean sea level)	1000 m
Overvoltage category	II
Pollution degree	2
EMC	light industrial

Mechanical - XTA

The outline drawing of the XTA is shown in Figure 2.1. It comprises the forcer with an integrated plastic sleeve bearing and the thrust rod. The integrated bearing acts as a guide for the moving thrust rod. It is not intended to withstand side loading. If side loading is expected then it is advised that an external bearing is fitted.

The XTA forcer can be mounted by two methods.

- Using the T -slots in the top of the forcer.
- Using M6 fixings (4 off) on the end flange.

IMPORTANT

When using the end flange fixing method, the fixings and mounting plate must be of a non-ferrous material such as aluminum, stainless steel, and plastic for example.

Dimensional details for both are given in Figure 2.1.

The recommended tightening torque for the fixings are:

M6 end flange 9 Nm M6 T-nut 10 Nm (both non lubricated i.e. no thread lock)

The thrust rod has optional male and female threaded connections at each end. These are intended to interface to a number of standard accessories. The thrust rod has an external circlip at each end to restrain the thrust rod within the forcer. These are not intended as "hard stops" to prevent over-travel and it is the responsibility of the User to prevent the thrust rod from being ejected from the forcer.

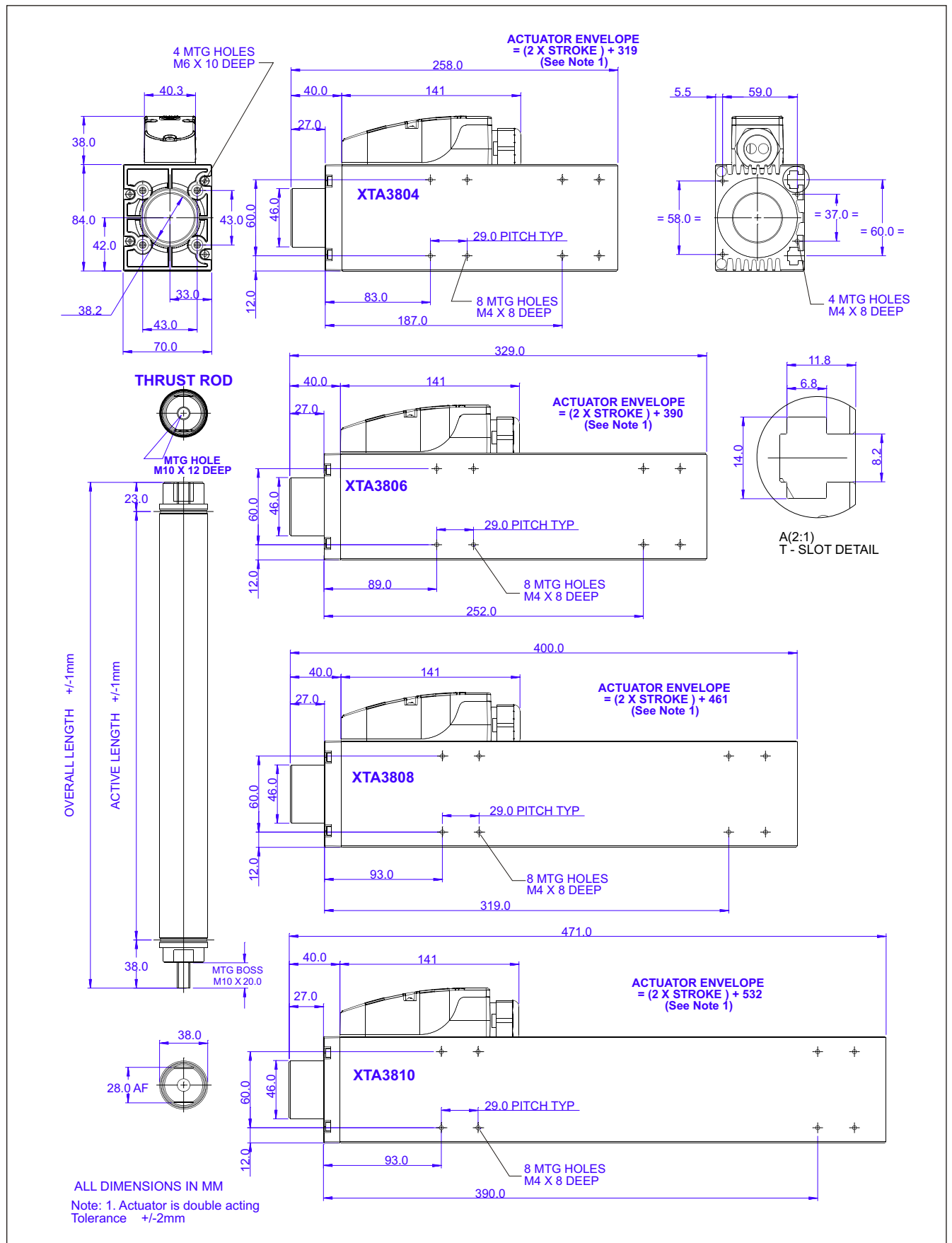


Figure 2.1 - XTA Outline drawings and mounting details

Mechanical - XTB

The XTB is shown in Figure 2.2. It comprises the forcer and the thrust rod. With the addition of thrust rod supports and a linear bearing a moving forcer solution can be implemented.

The XTB forcer can be mounted by two methods. T-slots are available in the top of the forcer but more normally the forcer is mounted to bearing carriages to allow the use of a linear bearing. Dimensional details for both are shown in Figure 2.2. The recommended tightening torque for the fixings are:

M4 bearing to forcer	4 Nm	M6 T-nut	10 Nm
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The thrust rod can be mounted using thrust rod supports (part number 400 885 361). The thrust rod support comprises a split clamp with two M10 pinch bolts.

All torque figures are non-lubricated i.e. no thread lock.

As the XTB has a moving forcer it is supplied with highly flexible cables suitable for continuous flexing operation. In order to achieve the best reliability and life from these cables it is advised that some form of cable management system is used. Typically, this will be an energy chain mounted parallel to the direction of motion. Always follow the manufacturers recommendations when installing cables into energy chains. In particular:

- Observe cable minimum bend radius requirements (see Appendices).
- Never allow the cable to be under tension within the energy chain.
- Physically separate cables within the energy chain to prevent premature failure due to abrasion.
- Never cross cables within the energy chain.
- Be careful to prevent the cable from twisting or becoming kinked during installation into the energy chain.

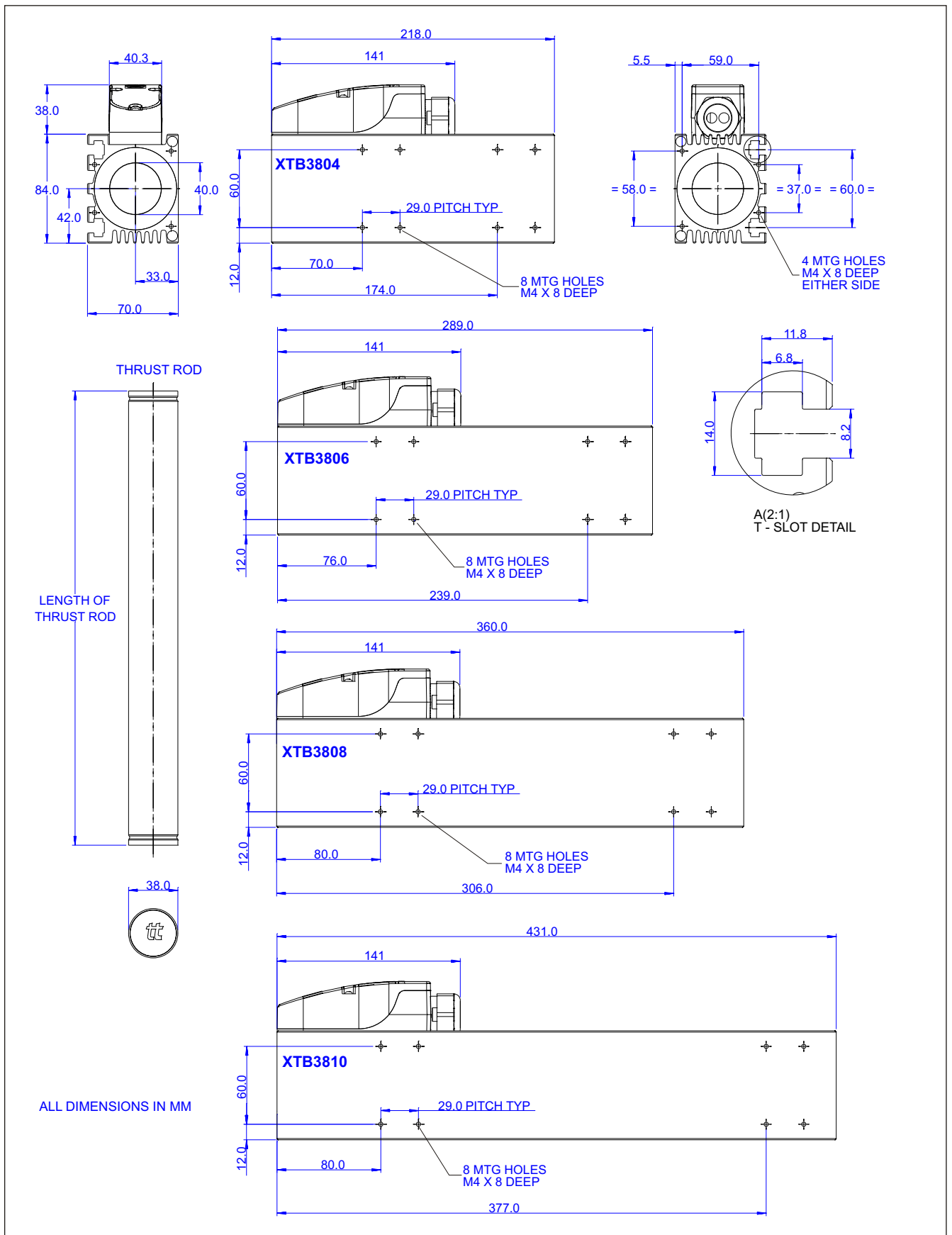


Figure 2.2 - XTB Outline drawings and mounting details



Electrical

All electrical connections to the XTA and XTB are made via two cables, see Figure 2.3. One carries power to the forcer and the other carries signals from the position sensor. These cables are supplied either pre-terminated for a specific drive or with flying leads. Where they are pre-terminated, simply plug the cables into the relevant connectors on the drive:

Forcer Power Connector reference	Position sensor connector reference	Amplifier
J2	J8	Copley Xenus
X3	X13	Parker Compax 3

For cable reference numbers refer to Chapter 4 - Service.



WARNING

THE THRUST ROD ON BOTH XTA AND XTB MUST BE EARTHED. THIS CAN BE ACHIEVED BY EARTHING THE CONNECTED MECHANICAL PARTS ON THE USER'S MACHINE.

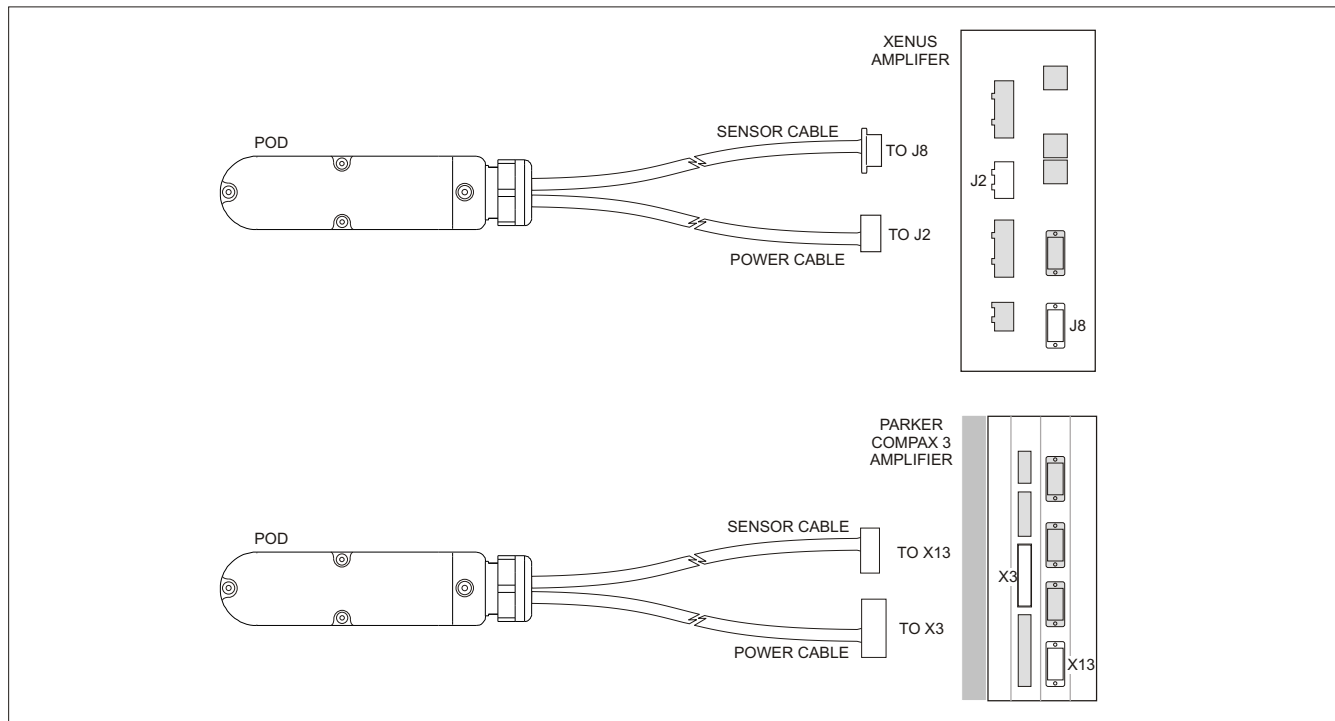


Figure 2.3 - Schematic showing connection of XTA / XTB to the Xenus Amplifier and Parker Compax 3 Amplifier

Chapter 3 Maintenance



XTA

The XTA is low maintenance and as such requires only minimal periodic inspection.

The integral bearing is dry running, requiring no lubrication.

Periodically:

- Check that the thrust rod can move freely over the entire stroke.
- Clean any accumulated debris from the thrust rod surface (ferrous material, in particular, can be attracted to the thrust rod surface).
- Check all fixings are tight and secure.

XTB

The XTB is low maintenance and as such requires only minimal periodic inspection.

Where an external linear bearing is used, please consult the bearing manufacturer for recommendations on lubrication types and lubrication intervals.

Periodically:

- Check that the forcer can move freely over the entire stroke.
- Clean any accumulated debris from the thrust rod surface (ferrous material, in particular, can be attracted to the thrust rod surface).
- Check all fixings are tight and secure.
- Check all flexing cables for signs of wear or damage.



WARNING

ISOLATE AND DISCONNECT ALL SOURCES OF ELECTRICAL SUPPLY BEFORE WORKING ON THE EQUIPMENT.

CABLE REPLACEMENT

If a cable needs to be replaced it will be necessary to gain access to the termination box inside the pod, see Figure 3.1.

Removal

- Unscrew the four M3 pod cover fixings.
Note that the fixings are of different lengths.
Make a record from where each fixing is removed so they can be correctly replaced later.
- Remove the pod cover from the termination box.
- Unscrew the pressure nut from the cable gland.
- Disconnect the power cable from the screw terminal connector, TB1 and the earth terminal and/or unplug the sensor cable from the PCB at connector PL1.

- Loosen the two fixings on the cable clamp.
- Pull the cable out through the cable gland.

Replacement

Re-fitting is the reverse of the removal procedure.

- Feed the new cable(s) through the cable gland.
- Connect the cable(s) including the earth lead.
- Tighten the cable retaining clamp.
- Take care not to damage the sealing gasket on the termination box when replacing the cover.
- Replace the fixings according to the record made when they were removed.
- Tighten the four M3 fixings to a torque of 0.7 Nm.

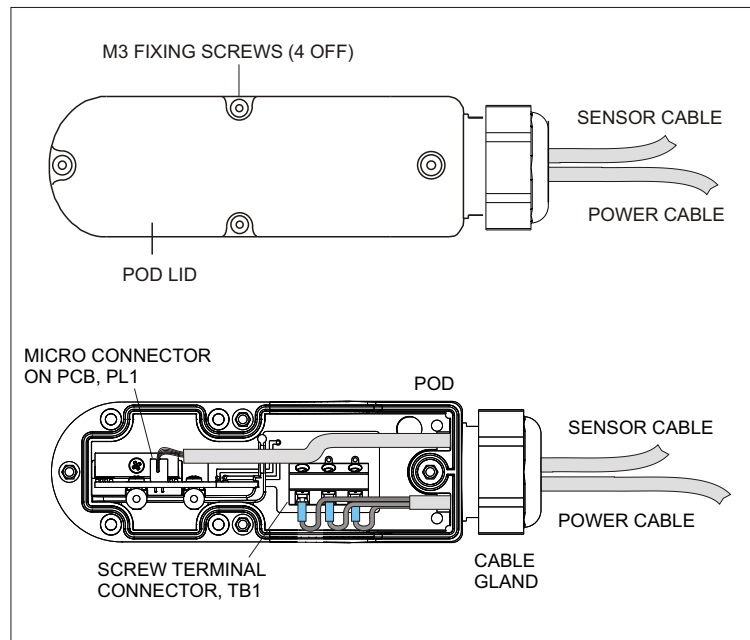


Figure 3.1 - Power and Sensor cable connection details in the pod

Chapter 4

Service

SERVICE

Should you need to return any items to Copley Motion Systems, before doing so, please call our Sales co-ordinator on +44 (0)1268 287070 or send a fax to +44 (0)1268 293344 in order to obtain an RMA (Returned Materials Authorisation) number. The RMA number should then be quoted on all items returned and quoted for all enquiries.

Please note that when returning items it is recommended that the original packaging be used.

SPARES

The available spares for the XTA and XTB are listed in Tables 4.1 and 4.2.

Table 4.1 Cables available: terminated for Xenus, Parker Compax 3 and with flying leads

Description	Xenus	Parker Compax 3	Flying leads
<i>Non-flexing cables</i>			
XTA power cable 3m	450 477 003A	450 477 083A	450 477 043A
XTA sensor cable 3m	450 477 023	450 477 103	450 477 063
XTA power cable 5m	450 477 005A	450 477 085A	450 477 045A
XTA sensor cable 5m	450 477 025	450 477 105	450 477 065
<i>Flexing cables</i>			
XTB power cable 3m	450 477 003	450 477 083	450 477 043
XTB sensor cable 3m	450 477 023	450 477 103	450 477 063
XTB power cable 5m	450 477 005	450 477 085	450 477 045
XTB sensor cable 5m	450 477 025	450 477 105	450 477 065

Table 4.2 Hardware

Description	Order Code
M6 T-nut	046 205 007
Circlip - stainless steel	400 870 138

To place an order for spare parts please telephone or fax your order to the Sales co-ordinator:

Tel: +44 (0)1268 287070
Fax: +44 (0)1268 293344

Appendices

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APPENDIX A - GLOSSARY OF TERMS & ABBREVIATIONS

APPENDIX B - TROUBLE SHOOTING

APPENDIX C - TECHNICAL SPECIFICATION

Appendix A

Glossary of Terms & Abbreviations

GLOSSARY OF TERMS

TERM	DESCRIPTION OF TERM
Peak force	<p>Peak force is the force produced when the peak current is applied to the motor. It is the product of Force constant (N/A_{pk}) and Peak current (A_{pk}).</p> <p>The motor is not moving, there is no forced cooling and no additional heat-sinking. The duration of the peak force is thermally limited and is therefore only allowable for a period of 1 second.</p>
Continuous stall force	<p>Continuous stall force is the force produced when the continuous current is applied to the motor. It is the product : Force constant (N/A_{pk}) x Continuous stall current (A_{pk}) or : Force constant (N/A_{rms}) x Continuous stall current (A_{rms}).</p> <p>The motor is not moving and there is no forced cooling.</p> <p>It is quoted with and without the addition of a 25 x 25 x 2.5 cm heatsink plate mounted with thermal grease to the mounting surface of the motor.</p>
Peak current	<p>Peak current is the current required to heat the motor phases to their maximum operating temperature when the ambient temperature is 25°C, the motor is not moving, there is no forced cooling and no additional heat-sinking.</p> <p>It is the maximum allowable current before demagnetisation of the magnets occurs when the magnet temperature is 100°C.</p> <p>The duration of the peak current is thermally limited and is therefore only allowable for a period of 1 second.</p>
Continuous stall current	<p>Continuous stall current is the current required to heat the motor phases to their maximum operating temperature when the ambient temperature is 25°C, the motor is not moving and there is no forced cooling.</p> <p>It is quoted with and without the addition of a 25 x 25 x 2.5 cm heatsink plate mounted with thermal grease to the mounting surface of the motor.</p>
Force constant	<p>Force constant is the peak force produced when 1 ampere (peak) flows into one phase and 0.5 ampere (peak) flows out of the remaining two phases (as in sinusoidal commutation) quoted in N/A_{pk}. Alternatively, it is the peak force produced when 0.707 ampere (rms) flows into one phase and 0.353 ampere (rms) flows out of the remaining two phases (again as in sinusoidal commutation) quoted in N/A_{rms}.</p>
Back EMF	<p>Back EMF constant is the peak phase to phase voltage generated when the motor is travelling at a velocity of 1m/s.</p>
Fundamental motor constant	<p>Fundamental motor constant is the continuous stall force divided by the square root of the power dissipated in the motor at that continuous stall force.</p>
Eddy current loss	<p>Eddy current loss is the amount of opposing force produced by the motor when it is travelling at a velocity of 1m/s.</p>
Sleeve clogging force	<p>Sleeve clogging force is the amount of force variation produced by having an iron sleeve. The variation is independant of motor current.</p>
Resistance	<p>Resistance is measured phase to phase at temperatures of 25°C and 100°C.</p>
Inductance	<p>Inductance is measured phase to phase at a frequency of 1 kHz. The actual value of inductance varies as the motor position varies so it is the minimum value that is quoted.</p>

TERM	DESCRIPTION OF TERM
Electrical time constant	Electrical time constant is the time taken for a step current input to the motor to reach 63.2% of its value.
Continuous working voltage	Continuous working voltage is the maximum allowable continuous voltage between any two motor phases or between any motor phase and the motor safety earth.
Pole pitch	Pole pitch is the distance in millimetres for one complete electrical cycle (between like magnetic poles).
Power dissipation	Power dissipation is the maximum power that can be dissipated by the motor when the motor phases are at their maximum operating temperature, the ambient temperature is 25°C, the motor is not moving and there is no forced cooling. It is quoted with and without the addition of a 25 x 25 x 2.5cm heatsink plate mounted with thermal grease to the mounting surface of the motor.
Maximum phase temperature	Maximum phase temperature is the maximum operating temperature for the motor phases. It is limited to provide a safe operating temperature for the magnets.
$R_{th\text{phase-housing}}$	$R_{th\text{phase-housing}}$ is the temperature rise from the motor housing to the motor phases for an input power of 1 watt to the motor. The motor is not moving, there is no forced cooling and no additional heatsinking.
$R_{th\text{housing-ambient}}$	$R_{th\text{housing-ambient}}$ is the temperature rise from ambient temperature to the motor housing for an input power of 1 watt to the motor. The motor is not moving and there is no forced cooling. It is quoted with and without the addition of a 25 x 25 x 2.5cm heatsink plate mounted with thermal grease to the mounting surface of the motor.
Thermal time constant	Thermal time constant is the time taken for the motor phases to cool to 36.8% of the difference between motor phase and ambient temperatures when there is no current flowing, the motor is not moving there is no forced cooling and no additional heatsinking.

ABBREVIATIONS

The abbreviations used in this Guide are listed in the following table.

A_{pk}	Ampere peak	PCB	Printed circuit board
A_{rms}	Ampere root mean square	PUR	Polyurethane
AWG	American Wire Gauge	PVC	Poly Vinyl Chloride
COS	cosine	s	second
d.c.	direct current	SIN	sine
EMC	Electro-Magnetic Compatibility	TYP	Typical
EMF	Electro-Motive Force	UL	Underwriters Laboratory
kg	kilogramme	V	Volt
m	metre	V_{pk}	Volt peak
mA	milliampere	V_{pk-pk}	Volt peak to peak
mH	millihenry	V_{rms}	Volt root mean square
mm	millimetre	W	Watt
MTG	Mounting	°C	degrees Celsius
N	Newton	μ	micrometre (micron)
PTC	Positive Temperature Coefficient		

Appendix B

Troubleshooting

TROUBLESHOOTING CHART

Check to see if the problem you are experiencing is listed in the chart below. If the problem cannot be solved with reference to this chart, contact the customer services department.

Fault	Possible cause	Action
Forcer/thrust rod fails to move and produces no force.	<ol style="list-style-type: none"> 1. Drive not powered. 2. Forcer phase connections not made. 3. Forcer over-temperature sensor not connected. 4. Forcer over-temperature. 	<ol style="list-style-type: none"> 1. Apply power to drive. 2. Check forcer phase connections on drive. 3. Check forcer over-temperature sensor connections on drive. 4. Allow forcer to cool.
Forcer/thrust rod fails to move but does produce force.	<ol style="list-style-type: none"> 1. One or more motor phase connections not made or made incorrectly. 2. One or more position sensor connections not made or made incorrectly. 3. Forcer/thrust rod mechanically blocked. 	<ol style="list-style-type: none"> 1. Check forcer phase connections on drive. 2. Check position sensor connections on drive. 3. Check forcer/thrust rod is free to move.
Forcer/thrust rod moves but is jerky in motion.	Incorrect pole pitch set up or phase offset between position sensor and forcer back emf.	Check drive or controller set up.
Forcer/thrust rod moves in wrong direction.	One or more position sensor and forcer phase connections made incorrectly.	Check position sensor and forcer phase connections on drive.

Appendix C

Technical Datasheet

ELECTRICAL SPECIFICATIONS

MOTOR TYPE	3804		3806		3808		3810		units
	S (1)	P (1)	S (1)	P (1)	S (1)	P (1)	S (1)	P (1)	
Peak force @ 25°C ambient for 1 sec	744	372	1116	558	1488	744	1860	930	N
Peak current @ 25°C ambient for 1 sec	20	20	20	20	20	20	20	20	A _{pk}
With 25 x 25 x 2.5 cm heatsink plate									
Continuous stall force @ 25°C ambient (2)	137.3	137.3	186.9	186.9	232.1	232.1	276.2	276.2	N
Continuous stall current @ 25°C ambient	2.61	5.23	2.37	4.74	2.20	4.41	2.10	4.20	A _{rms}
	3.69	7.39	3.35	6.71	3.12	6.23	2.97	5.94	A _{pk}
Without heatsink plate									
Continuous stall force @ 25°C ambient (2)	120.1		168.2		212.7		255.0		N
Continuous stall current @ 25°C ambient	2.28	4.57	2.13	4.27	2.02	4.04	1.94	3.88	A _{rms}
	3.23	6.46	3.01	6.03	2.86	5.72	2.74	5.49	A _{pk}
Force constant (sine commutation)	52.6	26.3	78.9	39.4	105.2	52.6	131.5	65.7	N/A _{rms}
	37.2	18.6	55.8	27.9	74.4	37.2	93.0	46.5	N/A _{pk}
Back EMF constant (phase to phase)	43.0	21.5	64.4	32.2	85.9	42.9	107.4	53.7	V _{pk} /m/s
Fundamental motor constant	14.54	14.54	17.80	17.80	20.56	20.56	22.99	22.99	N/ \sqrt{W}
Eddy current loss	3.7	3.7	3.7	3.7	3.7	3.7	3.7	3.7	N/m/s
Sleeve cogging force	7.3	7.3	4.2	4.2	8.3	8.3	5.6	5.6	+/-N
Resistance @ 25°C (phase to phase)	6.77	1.69	10.16	2.54	13.54	3.38	16.93	4.23	Ohm
Resistance @ 100°C (phase to phase)	8.73	2.18	13.10	3.27	17.45	4.36	21.82	5.45	Ohm
Inductance @ 1kHz (phase to phase)	8.52	2.13	12.78	3.19	17.04	4.26	21.30	5.32	mH
Electrical time constant	1.26	1.26	1.26	1.26	1.26	1.26	1.26	1.26	ms
Continuous working voltage	380	380	380	380	380	380	380	380	V d.c.
Pole pitch (one electrical cycle)	71.2	71.2	71.2	71.2	71.2	71.2	71.2	71.2	mm
XTA Peak acceleration (3)	250	125	313	156	357	179	391	196	m/s ²
XTA Maximum speed (4)	4.7	4.9	3.8	5.3	3.1	4.9	2.6	4.4	m/s
XTB Peak acceleration (5)	244	122	276	138	295	147	307	154	m/s ²
XTB Maximum speed (4)	6.2	9.4	4.5	7.6	3.5	6.2	2.8	5.2	m/s

Notes

- (1) S=series motor phases, P=parallel motor phases.
- (2) Reduce continuous stall force to 89% at 40°C ambient.
- (3) Based on a 33 mm stroke and no payload.
- (4) Based on triangular move over maximum stroke and no payload.
- (5) Based on a moving forcer and no payload.

THERMAL SPECIFICATIONS

MOTOR TYPE	3804	3806	3808	3810	units
Maximum phase temperature	100	100	100	100	°C
Thermal resistance $R_{th\text{phase-housing}}$	0.23	0.16	0.13	0.11	°C/W
With 25 x 25 x 2.5 cm heatsink plate					
Power dissipation @ 25°C ambient	89.3	110.3	127.1	144.2	Watt
Thermal resistance $R_{th\text{housing-ambient}}$	0.61	0.52	0.46	0.41	°C/W
Without heatsink plate					
Power dissipation @ 25°C ambient	68.2	89.3	107.0	123.0	Watt
Thermal resistance $R_{th\text{housing-ambient}}$	0.87	0.68	0.57	0.50	°C/W
Thermal time constant	1677	1798	1924	2056	s

MECHANICAL SPECIFICATIONS

MOTOR TYPE	XTA 3804	XTA 3806	XTA 3808	XTA 3810	XTB 3804	XTB 3806	XTB 3808	XTB 3810	units
Maximum stroke	318	318	318	318	1362	1291	1219	1148	mm
Forcer mass	2.75	3.75	4.75	5.75	2.55	3.55	4.55	5.55	kg
Forcer mass (including bearings)	-	-	-	-	3.05	4.05	5.05	6.05	kg
Thrust rod mass/metre	8.3	8.3	8.3	8.3	8.3	8.3	8.3	8.3	kg/m

POSITION SENSOR

The position sensor outputs analogue, differential sine and cosine signals for providing position feedback. Figure C.1 shows the relationships between motor phase back EMF and position sensor outputs for one direction of motion (as shown by arrows in Figures C.1 and C.2). It should be noted that +SIN or -SIN is always in phase with motor phase U. For the motion shown, -SIN is in phase with motor phase U. For motion in the opposing direction +SIN is in phase with motor phase U.

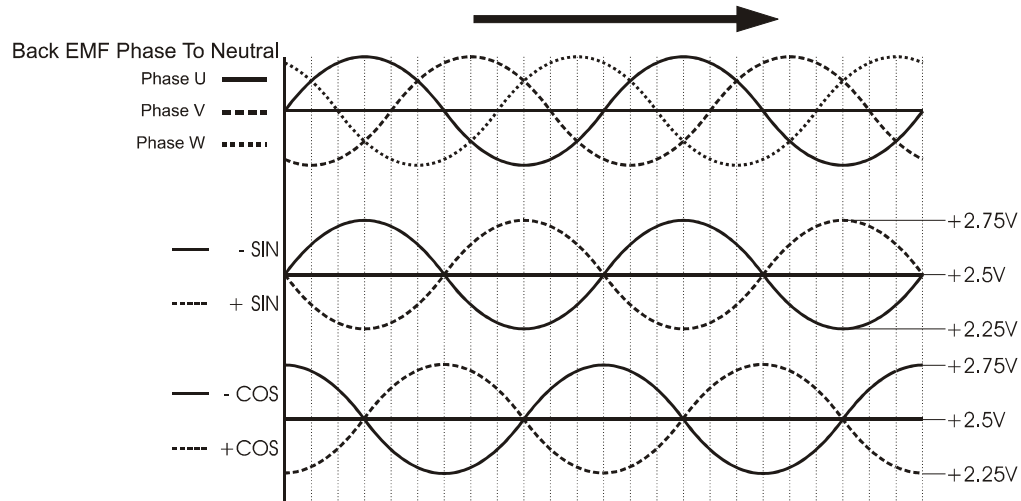


Figure C.1- The relationships between motor phase back EMF and position sensor outputs

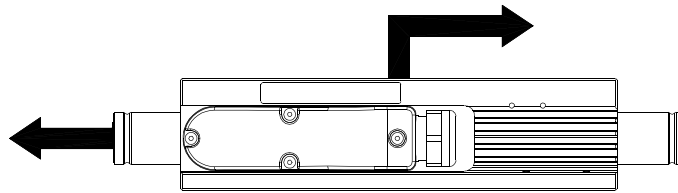


Figure C.2 - Arrows indicate direction of motion

SPECIFICATION	VALUE	UNITS
Output signal period	71.2	mm
Signal amplitude (between +/- signals)	1	V _{pk-pk}
Output current	±10	mA
Supply voltage	5 ± 0.25	V d.c.
Supply current (output current =0)	15 ± 5	mA
Resolution (1)	20	m
Position Repeatability (2)	±25	m
Absolute Accuracy (3)	±400	m/m

Notes

(1) Dependent on amplifier. (2) Dependent on amplifier. Under constant operating conditions. Self-heating of the thrust rod by the motor will cause expansion in the thrust rod during the initial warm up period. In high duty applications (corresponding to an internal motor temperature of 80°C) a 1 metre thrust rod will expand typically by 250 m. (3) Maximum error over 1metre under constant operating conditions.

MOTOR OVER TEMPERATURE SENSOR



It is strongly recommended that the motor over-temperature sensor is connected to the drive amplifier or servo controller at all times in order to reduce the risk of damage to the motor due to excessive temperatures.

Protection is provided by three, positive temperature coefficient (PTC) thermistors embedded in the motor phases. As the motor phase temperature approaches 100 °C, the PTC thermistors exhibit a sharp increase in electrical resistance. This change in resistance can be detected by circuitry within the drive amplifier or servo controller and used to reduce or disable the output of the drive amplifier in order to protect the motor.

SPECIFICATION	VALUE	UNITS
Resistance in the temperature range -20°C to +70°C	60 to 750	Ohms
Resistance at 85°C	1650	Ohms
Resistance at 95°C	<3990	Ohms
Resistance at 105°C	<12000	Ohms
Response time for a 20°C to 100°C temperature step to register a trip	3	s
Maximum continuous voltage	30	Vd.c.

CABLE

The XTA has two separate cables providing connections for motor power and position sensor. The standard cables supplied are flexible but are not intended for continuous flex or energy chain applications.

SPECIFICATION	POWER	SENSOR
Overall diameter (nominal)	8.2 mm	7.8 mm
Outer jacket material	PVC	PVC
Number of conductors	4	4 x twisted pair
Size of conductors	1.5mm ² (16 AWG)	0.14mm ² (26 AWG)
Screened / Unscreened	Screened	Screened
Operating voltage	600 V _{rms}	300 V _{rms}
Minimum bending radius-fixed routing	41 mm	40 mm
Operating temperature-fixed routing	-40 °C to + 90 °C	-40 °C to +70 °C
UL style	2586 105 °C 600 V	21083 90 °C 300 V

As an option, flexible cables are available that are suitable for continuous flex or energy chain applications. These cables are standard on the XTB.

SPECIFICATION	POWER	SENSOR
Overall diameter (nominal)	7.6 mm	7.8 mm
Outer jacket material	PUR	PVC
Number of conductors	4	4 x twisted pair
Size of conductors	1.5mm ² (16 AWG)	0.14mm ² (26 AWG)
Screened / Unscreened	Screened	Screened
Operating voltage	300 V _{rms}	300 V _{rms}
Minimum bending radius-flexible routing	38 mm	58 mm
Operating temperature-flexible routing	-40 °C to + 80 °C	+5 °C to +70 °C
UL style	20233 80 °C 300V	21083 90 °C 300 V

CONNECTIONS

Connections within the forcer termination box are as follows:

TB1	FUNCTION	CONDUCTOR DESIGNATION
1	Motor phase U	Black 1
2	Motor phase V	Black 2
3	Motor phase W	Black 3
Chassis	Protective earth + both cable screens	Green/Yellow

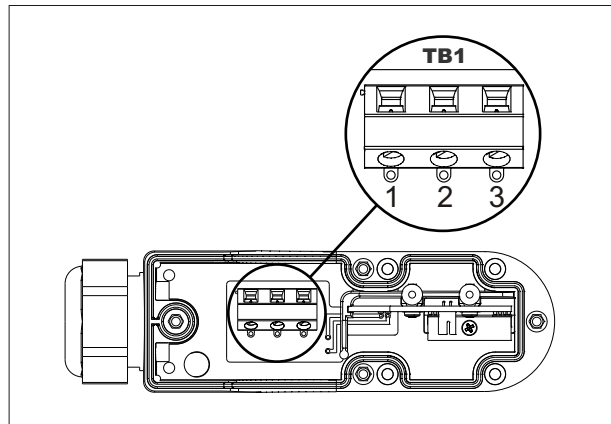


Figure C.4 - Power cable connection at TB1

	FUNCTION	CONDUCTOR DESIGNATION
1	+SIN	Blue
2	-SIN	Black paired with Blue
3	+COS	White
4	-COS	Black paired with White
5	+5Vd.c.	Red
6	0V	Black paired with Red
7	+TH (Thermistor)	Green
8	-TH (Thermistor)	Black paired with Green

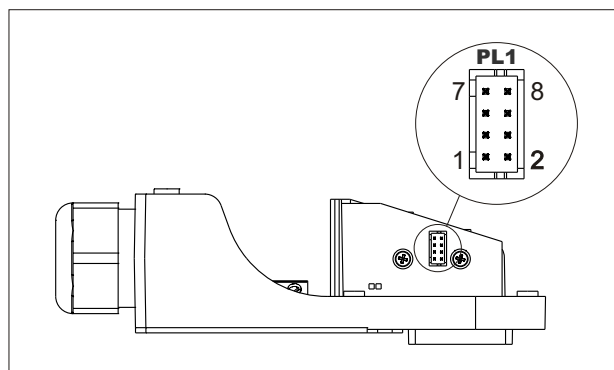


Figure C.5 - Sensor cable connection at PL1 on the Sensor PCB

XTA FORCE / VELOCITY PROFILES (WITH AN OPERATING VOLTAGE OF 325 V.D.C.)

S=series motor phases P=parallel motor phases

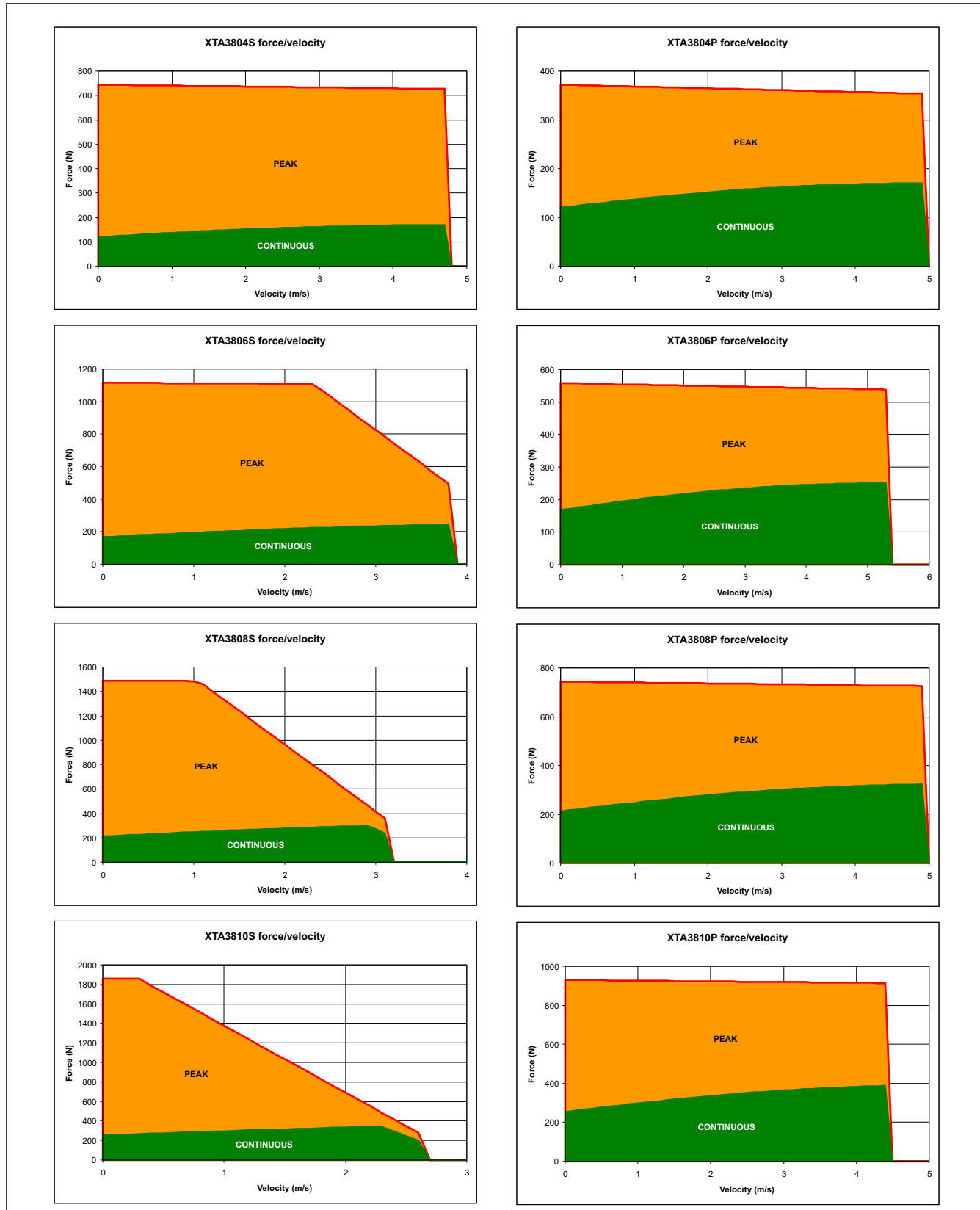


Figure C.6 - XTA force / velocity profiles

XTB FORCE / VELOCITY PROFILES (WITH AN OPERATING VOLTAGE OF 325 VD.C.)

S=series motor phases P=parallel motor phases

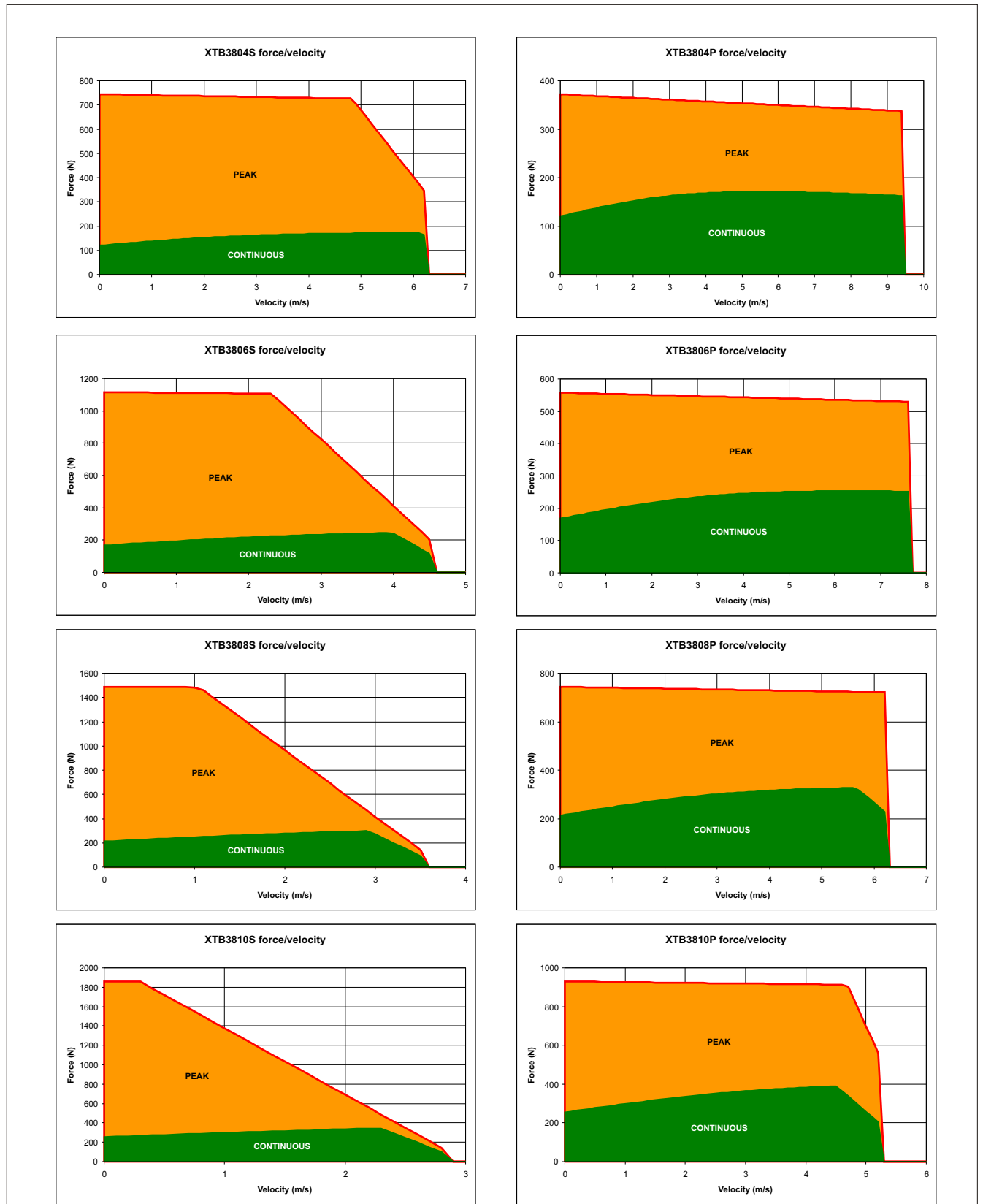


Figure C.7 - XTB force / velocity profiles



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